

A Locally Linear Transformations Based Forecasting Model For Dynamic State Systems

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Abstract

In this research investigation, the author has presented ‘*A Locally Linear Transformations Based Forecasting Model For Dynamic State Systems*’.

Theory

Firstly, we represent any *Dynamic State System* using a *State Vector (Row Vector)* of a specified size, say

$$V_i = [V_i(1) \ V_i(2) \ V_i(3) \ \dots \ V_i(n-2) \ V_i(n-1) \ V_i(n)]$$

That is,

$$\bar{V}_i = [V_i(1) \ V_i(2) \ V_i(3) \ \dots \ V_i(n-2) \ V_i(n-1) \ V_i(n)]$$

$$\bar{V}_i = \sum_{j=1}^n \{V_i(j)\hat{e}_j\}$$

Here, the *State Vector* has n parameters that are Evolving with time.

For the time instant $i = k$, we have the *State Vector* given by

$$\bar{V}_k = [V_k(1) \ V_k(2) \ V_k(3) \ \dots \ V_k(n-2) \ V_k(n-1) \ V_k(n)]$$

Let the *State Vector* be defined for $i = 1$ to $i = m$ instants.

We now *Normalize* all \bar{V}_i for $i = 1$ to $i = m$.

The *Normalization* is given by

$$\hat{V}_i = \frac{\bar{V}_i}{\left\{ \sum_{j=1}^n [V_i(j)]^2 \right\}^{1/2}}$$

That is,

$$\hat{V}_i = \frac{\sum_{j=1}^n \{ [V_i(j)] \hat{e}_j \}}{\left\{ \sum_{j=1}^n [V_i(j)]^2 \right\}^{1/2}}$$

We now calculate the *Diagonal Transformation Matrices* connecting each \hat{V}_i to \hat{V}_{i+1} , for $i = 1$ to $i = m$.

We label these as $T_{i \rightarrow (i+1)}$.

That is $\hat{V}_{i+1} = \hat{V}_i T_{i \rightarrow (i+1)}$

where the elements of $T_{i \rightarrow (i+1)}$ are given by

$$T_{i \rightarrow (i+1)}(j, j) = \frac{V_{i+1}(j)}{V_i(j)} \text{ for } j = 1 \text{ to } j = n$$

In order to *Forecast* \hat{V}_{m+1} we use

$$\hat{V}_{m+1} = \hat{V}_m T_{r \rightarrow (r+1)} \text{ where } 1 \leq r \leq (m-1)$$

where $T_{r \rightarrow (r+1)}$ satisfies $\hat{V}_{r+1} = \hat{V}_r T_{r \rightarrow (r+1)}$ where r is that particular r for which $(\hat{V}_m \cdot \hat{V}_i)$ is *Maximum* for $i = 1$ to $i = (m-1)$, where $(\hat{V}_m \cdot \hat{V}_i)$ indicates Euclidean Inner Product.

Finally, we arrive at the Magnitude of \hat{V}_{m+1} in the following fashion:

Case 1:

$$\bar{V}_{m+1}(j) = \{ \hat{V}_{m+1}(j) \} \{ |\bar{V}_m| \}$$

Case 2:

$$\bar{V}_{m+1}(j) = \{ \hat{V}_{m+1}(j) \} \{ |\bar{V}_r| \}$$

Case 3:

$$\bar{V}_{m+1}(j) = \left\{ \hat{V}_{m+1}(j) \right\} \left\{ \bar{V}_m(j) \right\} \left\{ \frac{\hat{V}_{m+1}(j)}{\hat{V}_{r+1}(j)} \right\}$$

That is,

$$\bar{V}_{m+1}(j) = \frac{\left\{ \hat{V}_{m+1}(j) \right\}^2 \left\{ \bar{V}_m(j) \right\}}{\left\{ \hat{V}_{r+1}(j) \right\}}$$

Case 4:

$$\bar{V}_{m+1}(j) = \frac{\left\{ \hat{V}_{m+1}(j) \right\}^2 \left\{ \bar{V}_m(j) \right\}}{\left\{ \hat{V}_m(j) \right\}}$$

Conclusion

This Scheme can be used to predict the *One Step Evolution* of any *Dynamic State System* with Large Number of Parameters.

Moral

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1. **One, Two, Three and N Dimensional String Search Algorithms**

Ramesh C. Bagadi

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Dedication

*All of the aforementioned Research Works, inclusive of this One are **Dedicated to Lord Shiva.***